

FIG. 1

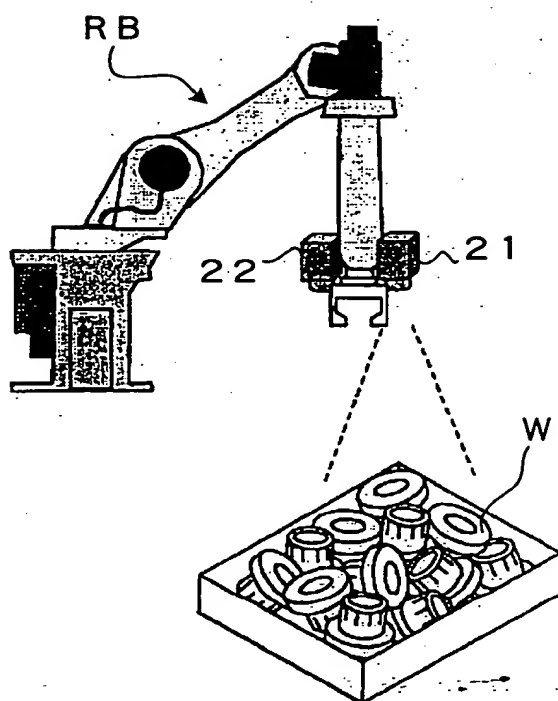


FIG. 2a

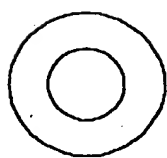


FIG. 2b

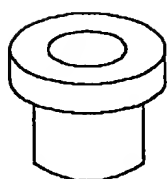


FIG. 2c

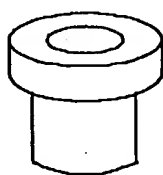
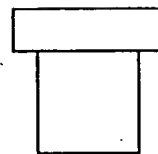


FIG. 2d



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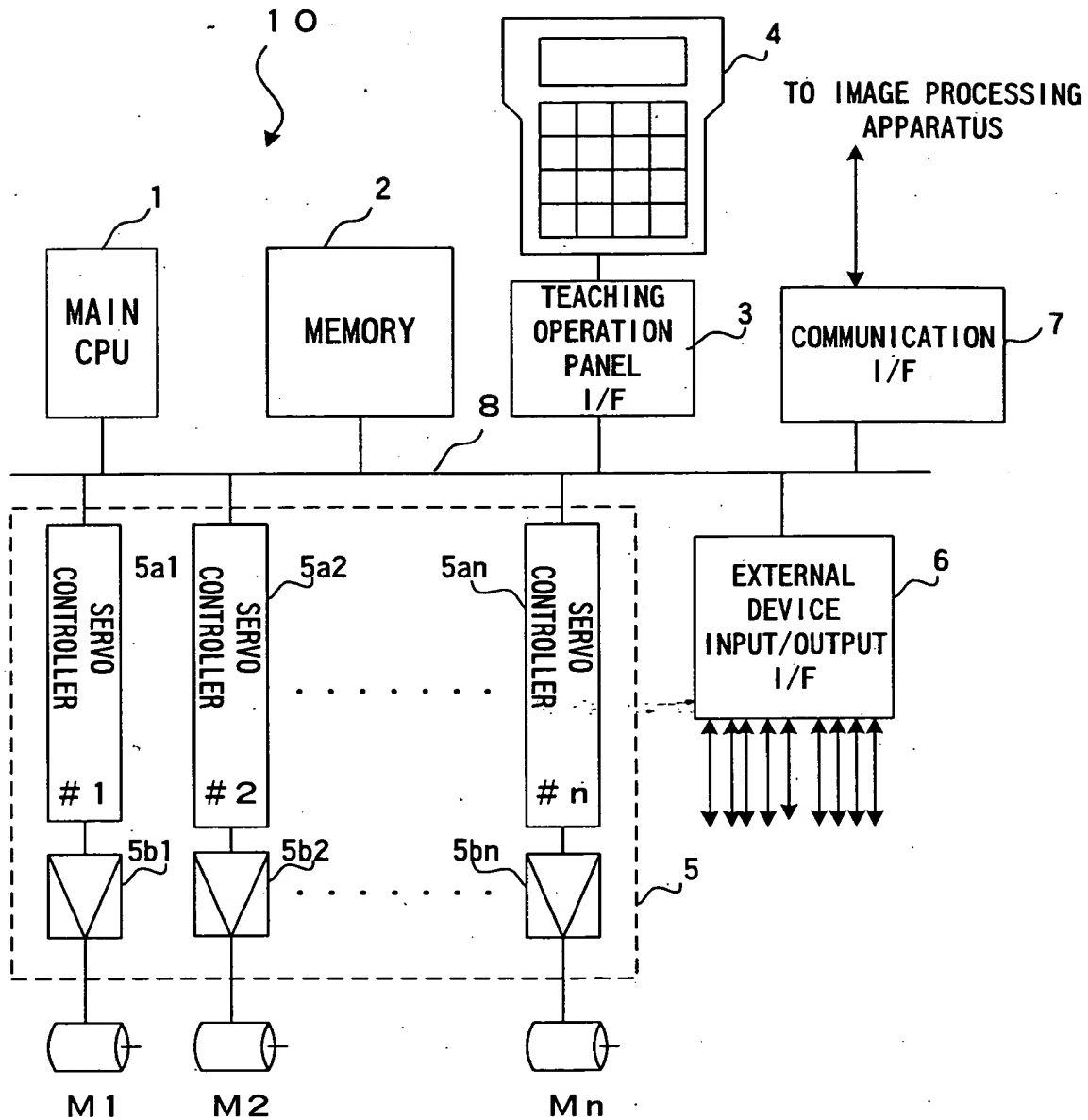


FIG. 4

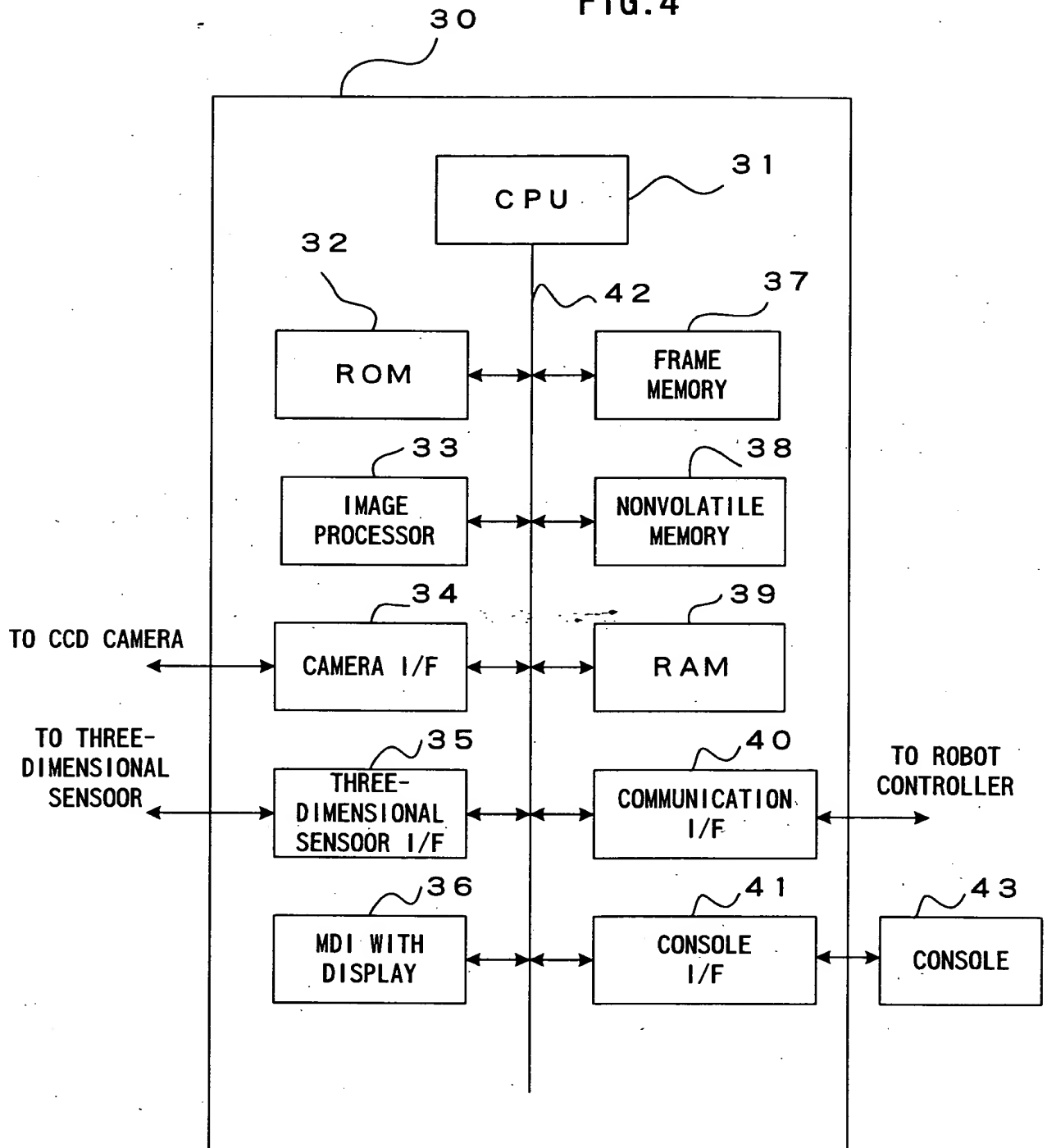


FIG.5

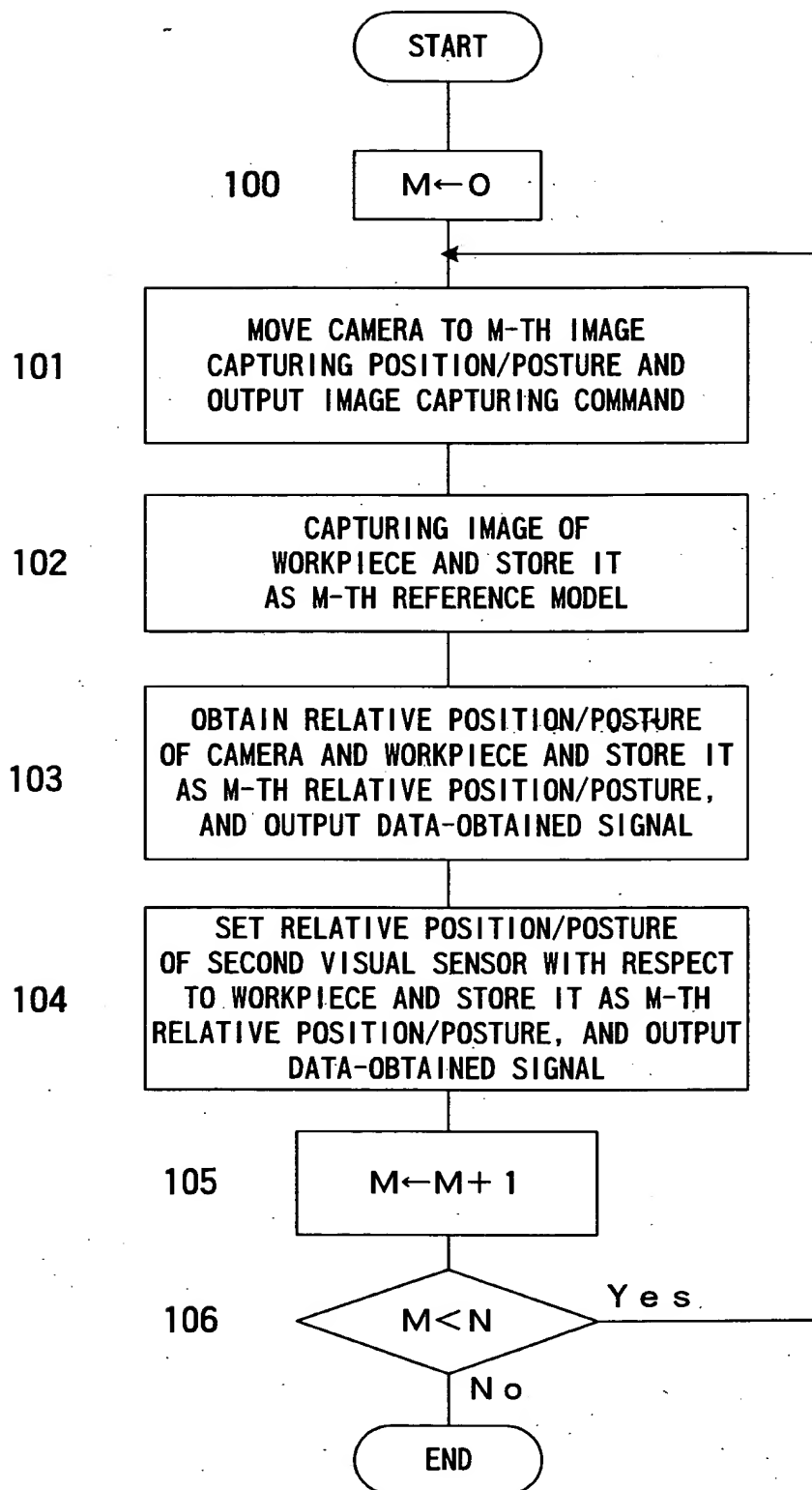




FIG.7

REFERENCE MODEL NO. (M)	FIRST-SENSOR RELATIVE POSITION/POSTURE [RELATIVE POSITION POSTURE OF WORKPIECE WITH RESPECT TO CAMERA] (X, Y, Z, α , β , γ) _c	WORKPIECE-ROBOT RELATIVE POSITION/POSTURE [RELATIVE POSITION POSTURE OF SECOND VISUAL SENSOR TO BE SITUATED WITH RESPECT TO WORKPIECE] (X, Y, Z, α , β , γ) _{wk}
0	10.0, -20.8, 50.5, 0.0, 0.0, 0.0	35.5, 20.5, 60.9, 0.0, 0.0, 0.0
1	10.0, -20.8, 50.5, 30.0, 0.0, 0.0	35.5, 20.5, 60.9, 0.0, 0.0, 0.0
2	10.0, -20.8, 50.5, 60.0, 0.0, 0.0	35.5, 20.5, 60.9, 0.0, 0.0, 0.0
3	10.0, -20.8, 50.5, 90.0, 0.0, 0.0	35.5, 20.5, 60.9, 0.0, 0.0, 0.0

FIG.8

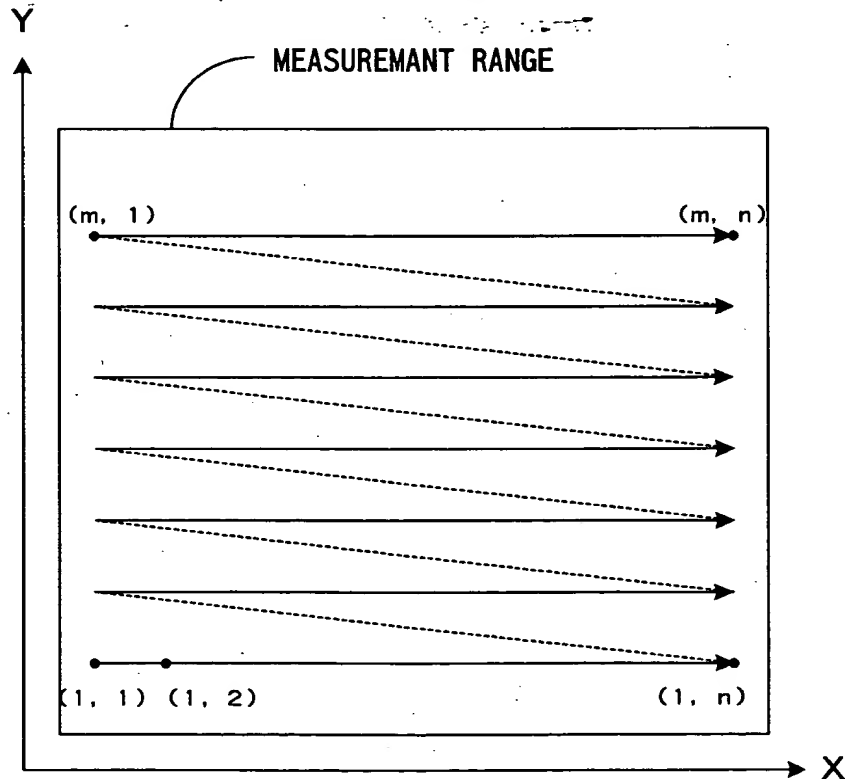
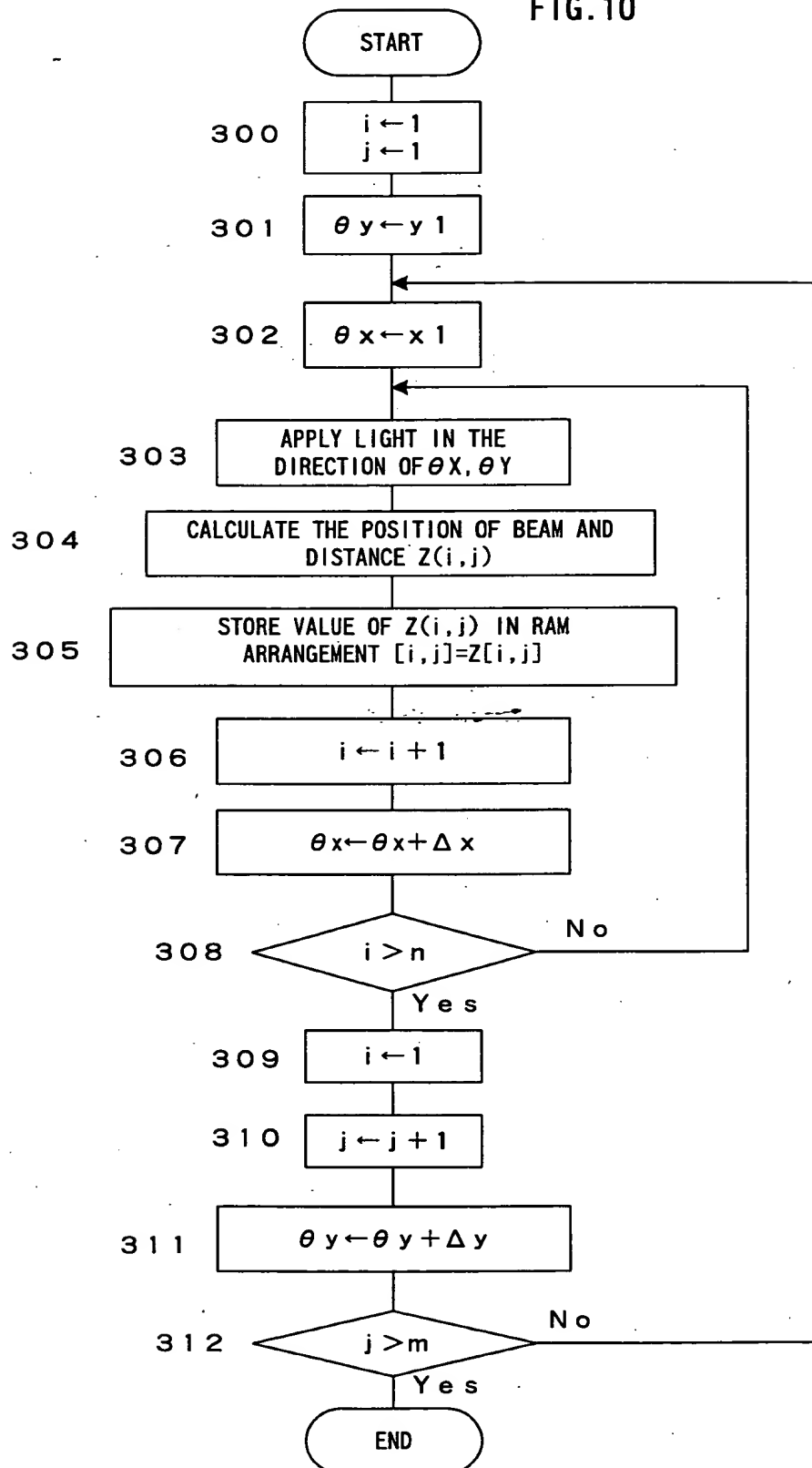


FIG.9

$Z(m,1)$	$Z(m,n)$
...
...
...	...	$Z(i,j)$
...
$Z(1,1)$	$Z(1,2)$	$Z(1,n)$

FIG. 10

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